

Amendments to the Claims

1. (Currently Amended) A rendering device for generating a drive assistant image of an area around a vehicle for drive assistance, said device comprising:

an image receiving part operable to receive images captured by a plurality of image capture devices, which are fixed in the vehicle respectively, operable to capture images of the area around the vehicle, the captured images include at least one overlapped region;

a steering angle receiving part operable to receive a steering angle of the vehicle detected by a steering angle sensor fixed in the vehicle;

a trajectory deriving part operable to derive an estimated trajectory for the vehicle to take based on the steering angle received by said steering angle receiving part; and

said vehicle includes a rudder angle sensor for detecting a rudder angle of the vehicle, and a plurality of image capture devices each for image capturing an area around the vehicle, and images captured thereby include an overlapped region,

said rendering device comprising:

an image receiving part for receiving the images captured by each of said image capture devices;

a rudder angle receiving part for receiving the rudder angle detected by said rudder angle sensor; and

an image processing part operable to perform for performing pixel selection from the captured images received by said image receiving part according to the steering rudder angle received by said steering rudder angle receiving part, and based on a result of the pixel selection, to generate the generating said drive assistant image, wherein

if the estimated trajectory derived by said trajectory deriving part is designated over an overlapped region, said image processing part is operable to select pixels from a captured image received by said image receiving part representing one side of the overlapped region with respect to an imaginary line, and to select pixels from another captured image representing the other side of the overlapped region with respect to the imaginary line, and

the imaginary line is one selected from a group including the estimated trajectory, a line displaced by a predetermined amount parallel to the estimated trajectory, and a chord of the estimated trajectory.

2. (Currently Amended) The rendering device according to claim 1, further comprising a table storing part operable to store for storing a mapping table showing a correspondence between the said drive assistant image and the said captured images on a pixel basis, wherein

in the said mapping table, a pixel belonging to the said overlapped region in the said drive assistant image corresponds to a plurality of pixels in the said captured images according to the steering rudder angle received by said steering rudder angle receiving part, and

according to the mapping table stored in said table storing part, said image processing part selects the pixels from each of the captured images received by said image receiving part.

3. (Currently Amended) The rendering device according to claim 1, further comprising:

~~a trajectory deriving part for deriving a trajectory estimated for said vehicle to take in a course of time based on the rudder angle received by said rudder angle receiving part; and~~

a trajectory rendering part operable to render for rendering the estimated trajectory derived by said trajectory deriving part on the drive assistant image generated by said image processing part.

4. (Currently Amended) The rendering device according to claim 1, further comprising:

an image storing part operable to store for storing a vehicle image representing the said vehicle; and

a vehicle rendering part operable to render for rendering the vehicle image stored in said image storing part on the drive assistant image generated by said image processing part.

5. (Currently Amended) The rendering device according to claim 1, wherein said image processing part generates the drive assistant image showing the area around the said vehicle viewed from a predetermined virtual camera.

6. (Currently Amended) A rendering method for generating a drive assistant image of an area around a vehicle for drive assistance, said method comprising:

receiving images captured by a plurality of image capture devices, which are fixed in the vehicle respectively, operable to capture images of the area around the vehicle, the captured images include at least one overlapped region;

receiving a steering angle of the vehicle detected by a steering angle sensor fixed in the vehicle;

deriving an estimated trajectory for the vehicle to take based on the received steering angle; and

~~said vehicle includes a rudder angle sensor for detecting a rudder angle of the vehicle, and a plurality of image capture devices each for image capturing an area around the vehicle, and images captured thereby include an overlapped region,~~

said rendering method comprising:

~~an image receiving step of receiving the images captured by each of said image capture devices;~~

~~a rudder angle receiving step of receiving the rudder angle detected by said rudder angle sensor; and~~

~~an image processing step of performing pixel selection from the received captured images received in said image receiving step according to the received steering rudder angle received in said rudder angle receiving step, and based on a result of the pixel selection, generating the said drive assistant image, wherein~~

if the estimated trajectory is designated an overlapped region, in said pixel selection, pixels are selected from a captured image representing one side of the overlapped region with respect to an imaginary line, and pixels are selected from another captured image representing the other side of the overlapped region with respect to the imaginary line, and

the imaginary line is one selected from a group including the estimated trajectory, a line displaced by a predetermined amount parallel to the estimated trajectory, and a chord of the estimated trajectory.

7. (Currently Amended) The rendering method according to claim 6, further comprising ~~storing a table storing step of storing a mapping table showing a correspondence between the said drive assistant image and the said captured images on a pixel basis, wherein~~

~~in the said mapping table, a pixel belonging to the said overlapped region in the said drive assistant image corresponds to a plurality of pixels in the said captured images according to the received steering rudder angle received in said rudder angle receiving step, and~~

~~according to the stored mapping table stored in said table receiving step, in said pixel selection image processing step, the pixels are selected from each of the received captured images received in said image receiving step.~~

8. (Currently Amended) A recording medium ~~having with~~ a program recorded ~~thereon~~ for generating a drive assistant image of ~~an area~~ around a vehicle for drive assistance, said program ~~including system readable instructions capable of instructing a system to perform the method comprising:~~

~~receiving images captured by a plurality of image capture devices, which are fixed in the vehicle respectively, operable to capture images of the area around the vehicle, the captured images include at least one overlapped region;~~

~~receiving a steering angle of the vehicle detected by a steering angle sensor fixed in the vehicle;~~

~~deriving an estimated trajectory for the vehicle to take based on the received steering angle; and~~

~~said vehicle includes a rudder angle sensor for detecting a rudder angle of the vehicle, and a plurality of image capture devices each for image capturing an area around the vehicle, and images captured thereby include an overlapped region;~~

~~said rendering method comprising:~~

~~an image receiving step of receiving the images captured by each of said image capture devices;~~

~~a rudder angle receiving step of receiving the rudder angle detected by said rudder angle sensor; and~~

an image processing step of performing pixel selection from the received captured images received in said image receiving step according to the received steering rudder angle received in said rudder angle receiving step, and based on a result of the pixel selection, generating the said drive assistant image, wherein

if the estimated trajectory is designated an overlapped region, in said pixel selection, pixels are selected from a captured image representing one side of the overlapped region with respect to an imaginary line, and pixels are selected from another captured image representing the other side of the overlapped region with respect to the imaginary line, and

the imaginary line is one selected from a group including the estimated trajectory, a line displaced by a predetermined amount parallel to the estimated trajectory, and a chord of the estimated trajectory.

9. (Currently Amended) The recording medium having with the program recorded thereon according to claim 8, further including system readable instructions capable of instructing a system to additionally store comprising a table storing step of storing a mapping table showing a correspondence between the said drive assistant image and the said captured images on a pixel basis, wherein

in the said mapping table, a pixel belonging to the said overlapped region in the said drive assistant image corresponds to a plurality of pixels in the said captured images according to the received steering rudder angle received in said rudder angle receiving step, and

according to the stored mapping table stored in said table receiving step, in said pixel selection image processing step, the pixels are selected from each of the received captured images received in said image receiving step.

10. (Currently Amended) A signal operable to instruct a system to generate program for generating a drive assistant image of an area around a vehicle for drive assistance, said signal including system detachable instructions capable of instructing the system to perform the method comprising:

receiving images captured by a plurality of image capture devices, which are fixed in the vehicle respectively, operable to capture images of the area around the vehicle, the captured images include at least one overlapped region;

receiving a steering angle of the vehicle detected by a steering angle sensor fixed in the vehicle;

deriving an estimated trajectory for the vehicle to take based on the received steering angle; and

~~said vehicle includes a rudder angle sensor for detecting a rudder angle of the vehicle, and a plurality of image capture devices each for image capturing an area around the vehicle, and images captured thereby include an overlapped region,~~

~~said rendering method comprising:~~

~~an image receiving step of receiving the images captured by each of said image capture devices;~~

~~a rudder angle receiving step of receiving the rudder angle detected by said rudder angle sensor; and~~

~~an image processing step of performing pixel selection from the received captured images received in said image receiving step according to the received steering rudder angle received in said rudder angle receiving step, and based on a result of the pixel selection, generating the said drive assistant image, wherein~~

if the estimated trajectory is designated an overlapped region, in said pixel selection, pixels are selected from a captured image representing one side of the overlapped region with respect to an imaginary line, and pixels are selected from another captured image representing the other side of the overlapped region with respect to the imaginary line, and

the imaginary line is one selected from a group including the estimated trajectory, a line displaced by a predetermined amount parallel to the estimated trajectory, and a chord of the estimated trajectory.

11. (Currently Amended) The signal program according to claim 10, further including system detachable instructions capable of instructing the system to further store comprising a table storing step of storing a mapping table showing a correspondence between the said drive assistant image and the said captured images on a pixel basis, wherein

in the said mapping table, a pixel belonging to the said overlapped region in the said drive assistant image corresponds to a plurality of pixels in the said captured images according to the received steering rudder angle received in said rudder angle receiving step, and

according to the stored mapping table stored in said table receiving step, in said pixel selection image processing step, the pixels are selected from each of the received captured images received in said image receiving step.